

**HEAD POSITIONING METHOD, AND
DISK APPARATUS USING THE SAME**

BACKGROUND OF THE INVENTION

5 **Field of the Invention**

The present invention relates to a positioning method for positioning a head, such as a magnetic head, an optical pickup, or the like, on a desired position of a target track of a disk (recording medium) with high precision by using a general adjustment actuator and a fine adjustment actuator. The present invention further relates to a disk 10 apparatus using such a control method.

Description of the Prior Art

In recent years, disk apparatuses, such as magnetic disk apparatuses, and the like, have been improved rapidly by decreasing the size and increasing the capacity 15 thereof. For example, the capacity of a magnetic disk apparatus has been increased by increasing the track density of the magnetic disk, and the track pitch will be further reduced in the future. Therefore, in order to record/reproduce data to/from a magnetic disk, it is necessary to precisely position a magnetic head on concentrical tracks formed at a small pitch.

20 Generally, a magnetic head is supported by a head supporting mechanism provided in a magnetic disk apparatus. FIG. 9 is a plan view showing an exemplary structure of a conventional head supporting mechanism. A magnetic head 102 for recording/reproducing data to/from a spinning magnetic disk 101 is supported at an end of a suspension arm (also referred to as "supporting arm") 103. The other end of the 25 suspension arm 103 is supported at an end of a carriage (also referred to as "base

arm") 104. The carriage 104 is rotatably supported by a rotational bearing 105 which is fixed to a housing (not shown) of the magnetic disk apparatus.

A coil 106, which is a constituent of a voice coil motor (VCM), is fixed at the other end of the carriage 104. A magnetic circuit including a magnet 107 is fixed to the 5 housing. The magnetic circuit controls a magnetizing current flowing through the coil 106 so that the carriage 104 pivots about the rotational bearing 105. With such a mechanism, the magnetic head 102, which is supported at the one end of the suspension arm 103, moves substantially in a radial direction of the magnetic disk 101.

The magnetic disk 101 contains servo information which are recorded in 10 advance thereon at a predetermined angular interval. The magnetic head 102 is positioned based on the servo information. Specifically, in the positioning process of the magnetic head 102, the magnetic head 102 reads the servo information to detect track position information of the magnetic head 102. The magnetic head 102 generates a position error signal which indicates the position error of the magnetic head 102 with respect to a target 15 track. The magnetic head 102 is positioned such that the position error signal is minimized. Such a positioning process is performed at every sampling cycle which is determined based on the rotation speed of the magnetic disk 101 and the number of pieces of servo information recorded in one track (the number of servo sectors in one track).

In order to precisely control the position of the magnetic head 102, it is 20 necessary to shorten the sampling cycle to increase the control frequency of a magnetic head positioning system. However, the head supporting mechanism shown in FIG. 9 may have a natural vibration mode of higher-order. In such a case, if the control frequency is increased for the purpose of increasing the positioning precision, the positioning system may become unstable due to the natural vibration. In the conventional head supporting 25 mechanism structure where the carriage 104 is rotated by the voice coil motor (VCM) 106

in order to position the magnetic head 102, it is difficult to achieve higher positioning precision.

As a countermeasure to such a problem, there have been proposed many implementations of a so-called “dual stage actuator” technique, wherein a fine adjustment actuator is further incorporated in the head supporting system, and the fine adjustment actuator is used in conjunction with the voice coil motor in order to precisely position a magnetic head. For example, in a proposed method, a thin film piezoelectric element which is capable of causing a tiny displacement and has a high natural resonance point is used as a fine adjustment actuator (see Japanese Unexamined Patent Publications 5 Nos. 2001-216748 and 2002-134807 (corresponding to United States Patent Application 10 Publication No. 2001/0021086 A1)). Another proposed method employs a servo technique in which a fine adjustment actuator is used in conjunction with a voice coil motor in order to position a magnetic head (see Japanese Patent No. 3089709).

On the other hand, as the size of magnetic disk apparatuses has been 15 decreased in recent years, disturbance such as the friction force in a rotational bearing supporting a head supporting mechanism or the elastic force of the flexible print circuit that connects the actuator with a circuit substrate, presents a factor that further deteriorates the positioning precision for the magnetic head. In view of this, there has been proposed a 20 positioning method for improving the positioning precision by compensating for such disturbance using disturbance estimation means. The disturbance estimation means operates based on a head position signal, which is extracted from servo information recorded on a magnetic disk, and a driving signal of the voice coil motor (see Japanese Unexamined Patent Publication No. 9-231701).

Increasing the control frequency of the magnetic head positioning system 25 such that the maximum quick-response performance is gained in the fine adjustment

actuator is a critical factor in the achievement of precise positioning of the magnetic head with the above-described dual stage actuator arrangement. However, in order to increase the control frequency, it is necessary to shorten the sampling cycle of sampling servo information. To this end, it is necessary to increase the number of servo sectors such that 5 more servo information are recorded on a magnetic disk. However, as more servo information are recorded, the user data area is accordingly decreased, resulting in a decrease in the data format efficiency.

For example, as shown in FIG. 10, in a disk 101, servo areas 110 containing servo information and user data areas 111 are provided at a predetermined angular interval. 10 For example, the length W_s of each servo area 110 and the length W_d of each user data area 111 for a 3.5-inch disk and a 1.8-inch disk are shown in the table of FIG. 11. As seen from FIG. 11, the length W_d of the user data area 111 decreases as the disk diameter decreases, but the length W_s of the servo area 110 does not decrease even if the disk diameter is decreased. This is because at least a certain amount of area is necessary for 15 recording the servo information, and the length W_s of the servo area 110 cannot be decreased in proportion to the disk diameter.

The ratio of the servo areas 110 to the total area of the disk 101 is represented as $W_s/(W_d+W_s)$. Thus, in the case of the 3.5-inch disk, the ratio is 50/(578+50)=8%. On the other hand, in the case of the 1.8-inch disk, the ratio is 20 50/(264+50)=16%. Thus, the ratio of the servo areas 110 to the total disk area increases as the disk size is decreased, resulting in a decrease in the data format efficiency.

In the above positioning method wherein disturbance is compensated for, the disturbance which acts on the head supporting mechanism is estimated based on the head position signal obtained from the servo information and the driving signal of the 25 voice coil motor in order to compensate for external force. However, the servo

information can be obtained only at every sampling cycle. Since this positioning method depends on the servo information, the band in which the disturbance can be estimated is limited by the sampling cycle of the servo information. As a result, the external force is not appropriately compensated for.

5 The present invention was conceived for the purpose of overcoming the above problems. An objective of the present invention is to provide a method for precisely positioning a head without increasing the number of servo sectors, i.e., without decreasing the data format efficiency. Another objective of the present invention is to provide a disk apparatus using such a positioning method.

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SUMMARY OF THE INVENTION

A head positioning method of the present invention is a method for positioning a head with respect to a rotating disk by using an actuator, the actuator including a general adjustment actuator which has a voice coil motor and has a stroke 15 covering the entire disk and a fine adjustment actuator which is interposed between the general adjustment actuator and the head and has a stroke smaller than that of the general adjustment actuator, the method comprising the steps of: generating a first driving signal for driving the general adjustment actuator and a second driving signal for driving the fine adjustment actuator; detecting a voltage generated in the voice coil motor due to the 20 driving of the general adjustment actuator to generate a voltage signal which indicates the detected voltage value; estimating the position of the head displaced due to the driving of the general adjustment actuator based on the first driving signal and the voltage signal to generate a first head position estimation signal; estimating a displacement of the fine adjustment actuator based on the second driving signal to generate a displacement 25 estimation signal; adding together the first head position estimation signal and the

displacement estimation signal to generate a second head position estimation signal; generating from a target position signal which indicates a target position of the head and the second head position estimation signal, a position error estimation signal which indicates an error of the head with respect to the target position; and correcting the first 5 driving signal and the second driving signal based on the position error estimation signal.

The position error estimation signal is generated independently of the sampling cycle of the servo information. Thus, according to the above method, even at the time when the servo information cannot be sampled, it is possible to estimate the position error, and it is possible to appropriately position the head.

10 Preferably, the positioning method further comprises the steps of: detecting the position of the head by reproducing, with the head, servo information recorded in advance on the disk; and generating a position error signal which indicates an error of the head with respect to the target position based on the detected head position and the target position; wherein the method includes, in place of the driving signal correction step, a 15 correction step of correcting the first driving signal and the second driving signal selectively using one of the position error signal and the position error estimation signal.

Preferably, the correction step is performed at a predetermined cycle that is shorter than a sampling cycle of the servo information; in a period during which the servo information is reproduced with the head, the position error signal is used; and in a period 20 during which the servo information is not reproduced with the head, the position error estimation signal is used.

With such features, the position error signal can be generated independently of the sampling cycle of the servo information, although the position error signal is generated at the sampling cycle of the servo information. Thus, at the time when the servo 25 information can be sampled, the positioning of the head is performed based on the position

error signal. On the other hand, at the time when the servo information cannot be sampled, the positioning of the head is performed based on the position error estimation signal. Accordingly, the sampling cycle is shortened without substantially increasing the number of servo sectors, and the control frequency of the head positioning system is increased. As 5 a result, precise head positioning is achieved without decreasing the data format efficiency.

Preferably, the positioning method further comprises the steps of: estimating the magnitude of disturbance acting on the general adjustment actuator based on the first driving signal and the voltage signal to generate a disturbance estimation signal; and generating from the disturbance estimation signal a disturbance compensation signal 10 which compensates for disturbance and synthesizing the first driving signal and the disturbance compensation signal to correct the first driving signal.

With such features, disturbance such as bearing friction, inertial force, etc., is compensated for, and the head positioning precision is improved.

Preferably, the head positioning method further comprises the steps of: 15 sequentially detecting the position of the head by reproducing, with the head, servo information recorded in advance on the disk; and after detecting the position of the head, sequentially correcting the first head position estimation signal based on the detected head position.

With such features, estimation of the head position shifted due to the 20 driving of the general adjustment actuator is carried out with more precision.

Preferably, the fine adjustment actuator is formed by a piezoelectric element. Preferably, the piezoelectric element has a characteristic that causes a displacement generally proportional to the second driving signal.

Since the displacement of the fine adjustment actuator is generally 25 proportional to the driving signal, the displacement estimation signal, which is an

estimation result for the displacement of the fine adjustment actuator, is readily and correctly generated.

A disk apparatus of the present invention comprises: a disk on which information is recorded; a motor for rotating the disk; a head for at least reproducing the information on the disk; a head supporting mechanism including a general adjustment actuator which has a voice coil motor and has a stroke covering the entire disk and a fine adjustment actuator which is interposed between the general adjustment actuator and the head and has a stroke smaller than that of the general adjustment actuator; a controller for generating a first driving signal and a second driving signal; a first driver for driving the general adjustment actuator according to the first driving signal; a second driver for driving the fine adjustment actuator according to the second driving signal; a voltage detector for detecting a voltage generated in the voice coil motor due to the driving of the general adjustment actuator to output a voltage signal which indicates the detected voltage value; a first estimator for estimating the position of the head displaced due to the driving of the general adjustment actuator based on the first driving signal and the voltage signal to output a first head position estimation signal; a second estimator for estimating a displacement of the fine adjustment actuator based on the second driving signal to output a displacement estimation signal; an adder for adding together the first head position estimation signal and the displacement estimation signal to output a second head position estimation signal; and a position error generator for generating from a target position signal which indicates a target position of the head and the second head position estimation signal, a position error estimation signal which indicates an error of the head with respect to the target position, wherein the controller corrects the first driving signal and the second driving signal based on the position error estimation signal.

25 Preferably, the position error generator generates a position error signal

which indicates an error of the head with respect to the target position by reproducing, with the head, servo information recorded in advance on the disk; and the controller corrects the first driving signal and the second driving signal selectively using one of the position error estimation signal and the position error signal.

5 Preferably, the controller corrects the first driving signal and the second driving signal at a predetermined cycle that is shorter than a sampling cycle of the servo information; in a period during which the servo information is reproduced with the head, the position error signal is used; and in a period during which the servo information is not reproduced with the head, the position error estimation signal is used.

10 Preferably, the disk apparatus further comprises a disturbance compensator for synthesizing a disturbance compensation signal which indicates an estimated magnitude of disturbance acting on the general adjustment actuator with the first driving signal to generate a disturbance-compensated first driving signal, wherein the first estimator estimates the magnitude of the disturbance acting on the general adjustment actuator based on the disturbance-compensated first driving signal and the voltage signal to generate the disturbance compensation signal.

15 Preferably, the first estimator sequentially corrects the first head position estimation signal based on the detected head position that is obtained by reproducing the servo information with the head.

20 Preferably, the fine adjustment actuator is formed by a piezoelectric element. Preferably, the piezoelectric element has a characteristic that causes a displacement generally proportional to the second driving signal.

25 As described above, according to the present invention, the positioning of the head can be carried out using the general adjustment actuator and the fine adjustment actuator even at the time when the servo information is not sampled. By employing the

method or structure of the present invention, it is possible to generate the position error signal independently of the sampling cycle of the servo information. Thus, it is possible to increase the control frequency of the head positioning system without increasing the number of servo sectors, i.e., without decreasing the data format efficiency.

5 At the same time when the head position estimation signal is generated, disturbance (such as the friction in the rotational bearing, the elastic force of the flexible print circuit, the impact or vibration on the disk apparatus, etc.) is estimated to compensate for the disturbance, whereby off-track due to disturbance is suppressed. As a result, the positioning of the head is stably and precisely carried out, and a highly reliable disk
10 apparatus is provided.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is a block diagram showing the structure of a principal part of a magnetic disk apparatus according to an embodiment of the present invention.

15 FIG. 2 is a block diagram showing a part of the structure of a positioning system according to an embodiment of the present invention.

FIG. 3A is a block diagram illustrating a disturbance suppressing operation according to an embodiment of the present invention. FIG. 3B shows a cutoff frequency characteristic against disturbance according to an embodiment of the present invention.

20 FIG. 4 is a block diagram showing another part of the structure of the positioning system according to an embodiment of the present invention.

FIG. 5A through FIG. 5C illustrate an example of the operation of a position error detector according to an embodiment of the present invention. FIG. 5A is a timing chart which illustrates the sampling times of servo information. FIG. 5B is a timing chart which illustrates the operation of a switch provided in the position error detector.
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FIG. 5C is a timing chart which illustrates the times of generation of a control signal.

FIG. 6 is a perspective view showing the structure of a suspension section including a fine adjustment actuator according to an embodiment of the present invention.

FIG. 7 is an exploded, enlarged perspective view which shows a slider 5 attachment section of the suspension section according to an embodiment of the present invention.

FIG. 8 illustrates an operation of a fine adjustment actuator formed by a thin film piezoelectric element according to an embodiment of the present invention.

FIG. 9 is a plan view showing an exemplary structure of a conventional 10 head supporting mechanism.

FIG. 10 is a conceptual diagram illustrating areas on a magnetic disk.

FIG. 11 shows the specifications of a 3.5"-disk and a 1.8"-disk.

DESCRIPTION OF THE PREFERRED EMBODIMENTS

15 Hereinafter, an embodiment of the present invention is described in detail with reference to the drawings.

FIG. 1 is a block diagram showing the structure of a principal part of a magnetic disk apparatus according to an embodiment of the present invention. Referring to FIG. 1, a magnetic disk 1 is spun by a spindle motor 95. A slider 2 has a magnetic 20 head 2a (see FIG. 6) mounted thereon, which records/reproduces data to/from the magnetic disk 1. The slider 2 is supported at an end of a suspension arm 3. The other end of the suspension arm 3 is supported at an end of a carriage 4. The carriage 4 is rotatably supported by a rotational bearing 5 which is fixed to a housing (not shown) of the magnetic disk apparatus.

25 Referring to FIG. 6, a fine adjustment actuator 7 which is formed by two

thin film piezoelectric elements 7a and 7b is mounted on the suspension arm 3. The suspension arm 3 is structured such that the voltages applied to the thin film piezoelectric elements 7a and 7b are controlled to cause a tiny displacement in the slider 2. FIG. 6 is a perspective view showing a side of a suspension 9 which faces the magnetic disk 1. On 5 this side of the suspension 9, the slider 2, the suspension arm 3, the fine adjustment actuator 7, etc., are provided. The suspension arm 3 is fixed to the carriage 4 at an end base portion 3a by, for example, welding, or the like. The suspension arm 3 includes a flexure element 3c which has a magnetic head wiring pattern and a wiring pattern for a thin film piezoelectric element. The flexure element 3c is patterned on a flexure substrate 3b.

10 FIG. 7 is an exploded, enlarged perspective view showing a slider attachment section which includes the flexure element 3c, the flexure substrate 3b, and a slider retaining plate 3d. The other side of a slider attaching section 3h of the flexure element 3c on which the slider 2 is not attached has the slider retaining plate 3d placed thereon. The slider retaining plate 3d has a protrusion 3e. The protrusion 3e abuts on a 15 dimple (not shown) formed at a tip of the suspension arm 3. Furthermore, the thin film piezoelectric elements 7a and 7b are adhered to the flexure element 3c as shown in FIG. 6.

FIG. 8 illustrates a rotational operation of the slider 2 which is performed when the thin film piezoelectric elements 7a and 7b are activated. When the thin film piezoelectric element 7a extends along direction A and the thin film piezoelectric element 7b contracts along direction B, the slider 2 and the slider retaining plate 3d rotates in direction C around the dimple abutting the protrusion 3e formed in the slider retaining plate 3d. Accordingly, the magnetic head 2a provided on the slider 2 moves in a radial direction of the magnetic disk 1. The widths of elastic hinge sections 3f and 3g have sufficient sizes for forming a magnetic head wiring pattern, but are formed in a size as 25 small as possible such that a load on the rotating slider 2 is decreased. Thus, the slider 2

surely rotates by extension/contraction of the thin film piezoelectric elements 7a and 7b.

The fine adjustment actuator 7 may be fabricated by a fabrication method disclosed in United States Patent Application Publication No. 2001/0021086 A1, which is incorporated herein by reference.

5 The voice coil motor (VCM) 6 is formed by a coil 6a and a magnet 6b which are constituents of a magnetic circuit. The coil 6a is fixed to the other end of the carriage 4. The magnet 6b is fixed to the housing. When an electric current flows through the coil 6a, rotational force is exerted on the carriage 4 due to an interaction between a magnetic flux generated by the electric current and a magnetic flux generated by the
10 magnetic circuit. Thus, by controlling the electric current supplied to the coil 6a, the slider 2 including the magnetic head 2a is allowed to move substantially in a radial direction of the magnetic disk 1.

The suspension arm 3, the carriage 4, the rotational bearing 5 and the voice coil motor 6 constitute the general adjustment actuator. A head supporting mechanism 8 is
15 formed by the slider 2, the suspension arm 3, the carriage 4, the rotational bearing 5, the voice coil motor 6 and the fine adjustment actuator 7.

Next, the entire structure of a control system for positioning the magnetic head 2a mounted on the slider 2 to a target position on the magnetic disk 1 using the head supporting mechanism 8 is described.

20 Referring to FIG. 1, a first driver 11 allows a driving current I_a corresponding to a voice coil motor driving signal u_1 to be passed through the coil 6a to drive the voice coil motor 6. A voltage detector 12 included in the first driver 11 detects the voltage which is generated between the both ends of the coil 6a due to the driving of the voice coil motor 6 to output a voltage signal V_a . A first estimator 13 estimates a
25 disturbance torque which acts on the head supporting mechanism 8 based on the voltage

signal V_a output from the voltage detector **12** and the voice coil motor driving signal u_1 which is also input to the first driver **11**, so as to output a disturbance estimation signal τ_{dest} . The first estimator **13** estimates the position of the magnetic head **2a** which has been displaced due to the driving of the voice coil motor **6**, so as to output a first head

5 position estimation signal x_{1est} .

A second driver **14** applies a driving voltage V_p corresponding to a fine adjustment actuator control signal c_2 to the fine adjustment actuator **7**. A second estimator **15** estimates the displacement of the magnetic head **2a** which has been caused due to the driving of the fine adjustment actuator **7** according to the fine adjustment

10 actuator control signal c_2 , so as to output a displacement estimation signal x_{2est} . An adder **16** adds together the first head position estimation signal x_{1est} output from the first estimator **13** and the displacement estimation signal x_{2est} output from the second estimator **15**, so as to output a second head position estimation signal x_{est} .

In the magnetic disk **1**, track position signals are recorded as servo

15 information in respective tracks at a predetermined angular interval. The position signals are read by the magnetic head **2a** at a predetermined sampling cycle. Receiving a head position signal x read by the magnetic head **2a** and the second head position estimation signal x_{est} , a position error detector **17** generates a position error signal e which indicates a difference between the current position of the magnetic head **2a** and a target position r of a

20 target track.

Receiving the position error signal e generated by the position error detector **17** and the displacement estimation signal x_{2est} output from the second estimator **15**, a first controller **18** generates a voice coil motor control signal c_1 . The voice coil motor control signal c_1 is input to a disturbance compensator **10** and synthesized with

25 the disturbance estimation signal τ_{dest} generated by the first estimator **13**. The disturbance

compensator 10 generates the voice coil motor driving signal u_1 from the voice coil motor control signal c_1 and the disturbance estimation signal τ_{dest} . Receiving the position error signal e generated by the position error detector 17, a second controller 19 generates the fine adjustment actuator control signal c_2 .

5 Next, an operation of a positioning system of a magnetic disk apparatus according to an embodiment of the present invention is described with reference to FIG. 2 through FIG. 5. Note that in FIG. 2 and FIG. 3, "s" represents a Laplace operator. Moreover, in FIG. 2, FIG. 3 and FIG. 4, the hold element occurring while sampling the servo information is omitted for the sake of simplicity.

10 FIG. 2 is a block diagram which illustrates the cooperation of the first driver 11, the voltage detector 12, the first estimator 13 and the disturbance compensator 10, which are components of the positioning system of the magnetic disk apparatus according to the present embodiment. In FIG. 2, the blocks corresponding to the elements of FIG. 1 are denoted by the same reference numerals used in FIG. 1.

15 The voice coil motor control signal c_1 output from the first controller 18 is converted to the voice coil motor driving signal u_1 through the disturbance compensator 10. The operation of the disturbance compensator 10 will be described later. In the first driver 11 which is represented by the block of transfer function "gm", the voice coil motor driving signal u_1 is converted from a voltage signal into a current signal that is 20 gm times the voltage signal. The resultant current signal is output as the driving current I_a . When the driving current I_a is passed through the coil 6a, a magnetic field is generated. By the interaction between the generated magnetic flux and a magnetic flux generated by the magnet 6b, a driving torque τ is generated in the voice coil motor 6. That is, the driving current I_a is converted by the voice coil motor 6 with a transfer function K_t into the 25 driving torque τ . Herein, the transfer function K_t represents the torque constant of the

voice coil motor 6. The transfer function ($Lb/J \cdot s$) of a block 23 represents the transfer characteristic from the driving torque τ generated by the voice coil motor 6 to the traveling velocity v of the magnetic head 2a. Herein, J denotes the moment of inertia of the head supporting mechanism 8, and Lb denotes the distance from the rotation center of the 5 rotational bearing 5 to the magnetic head 2a. A block 24 is an integrator, and the transfer function thereof is represented as $1/s$. The integrator 24 converts the traveling velocity v of the magnetic head 2a into the position x_1 of the magnetic head 2a which has been shifted due to the driving of the voice coil motor 6.

The disturbance τ_d acting upon the head supporting mechanism 8 (such as 10 the bearing friction in the rotational bearing 5, the elastic force of the flexible print circuit that connects the head supporting mechanism 8 with an electronic circuit substrate, or the inertial force acting upon the head supporting mechanism 8 from the external impact or vibration on the magnetic disk apparatus) is expressed in a form that is suitable as an input to an adder 27 preceding the block 23.

15 As the voice coil motor 6 drives, an induced voltage Ea proportional to the pivoting speed of the head supporting mechanism 8 occurs between the opposite ends of the coil 6a. The induced voltage Ea is expressed by Expression (1) where Kv represents a factor of proportionality.

$$Ea = \frac{Lb \cdot Kv}{J \cdot s} (\tau + \tau_d) \quad \dots (1)$$

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A one-dot-chain-line block including a block 26 and an adder 28 corresponds to the voltage detector 12 of FIG. 1. The voltage detector 12 outputs the voltage signal Va , which is produced at the adder 28 by adding together the induced

voltage E_a output from a block 25 and a voltage drop $(Ra + La \cdot s) \cdot I_a$ that occurs as the driving current I_a is passed through the coil 6a. The voltage signal V_a is expressed by Expression (2).

$$5 \quad V_a = E_a + (Ra + La \cdot s) \cdot I_a \quad \dots (2)$$

In this expression, R_a denotes the coil resistance of the coil 6a, and L_a denotes the inductance of the coil 6a. Based on Expression (1) and Expression (2), the voltage signal V_a is expressed as Expression (3).

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$$V_a = \frac{Lb \cdot Kv}{J \cdot s} (\tau + \tau_d) + (Ra + La \cdot s) \cdot I_a \quad \dots (3)$$

A one-dot-chain-line block on the lower right in FIG. 2 corresponds to the first estimator 13 of FIG. 1. The block 13 includes transfer functions represented by 15 blocks 31, 32, 33, 34, 35 and 36. The blocks 31-36 correspond to the blocks 21-26 and have substantially the same transfer functions as those of the blocks 21-26, respectively. In the disturbance estimator block 13, the suffix "n" to a constant indicates that it is a nominal value, and a variable with the "est" is an estimated value.

The voice coil motor driving signal u_1 , which is input to the first driver 11, 20 is also input to the first estimator 13. The voice coil motor driving signal u_1 is multiplied by $(gm_n \cdot Kt_n)$ through the block 31 and the block 32 to obtain a driving torque estimation signal τ_{est} , which is an estimated value of the driving torque τ generated by the voice coil motor 6.

A velocity estimation signal v_{est} is output from the block 33. The block 34

is an integrator, which has a transfer function of 1/s. The integrator 34 converts the velocity estimation signal v_{est} to the first head position estimation signal x_{1est} which represents an estimated position of the magnetic head 2a shifted due to the driving of the voice coil motor 6.

5 In the block 35, the velocity estimation signal v_{est} is multiplied by Kv_n to produce an induced voltage estimation signal Ea_{est} . The induced voltage estimation signal Ea_{est} and the voltage drop $(Ra_n+La_n \cdot s) \cdot Ia_{est}$, which occurs as a driving current estimation signal Ia_{est} is passed through the coil 6a, are added together by an adder 38, which outputs a voltage estimation signal Va_{est} . The voltage estimation signal Va_{est} is
10 input to a subtractor 39, where it is compared with the voltage signal Va actually detected by the voltage detector 12 to yield an error signal α ($=Va-Va_{est}$). The error signal α is input to a multiplier represented by a block 40 and to an integrator represented by a block 41. The integrator of the block 41 integrates the error signal α to output the disturbance estimation signal τ_{dest} indicating the estimated value of disturbance. The multiplier of the
15 block 40 multiplies the error signal α by G_1 and the multiplied signal is input to an adder 42. The adder 42 adds together the disturbance estimation signal τ_{dest} and the signal obtained by multiplying the error signal α by G_1 and inputs a resultant signal to an adder 37. The adder 37 adds together the driving torque estimation signal τ_{est} output from the block 32 and the output signal from the adder 42. A result γ of the addition is output to
20 the block 33.

Note that the coefficient G_1 of the block 40 and the coefficient G_2 of the block 41 are constants for stabilizing the operation of the first estimator 13, and will later be described in detail.

Another one-dot-chain-line block on the upper left in FIG. 12 corresponds
25 to the disturbance compensator 10 of FIG. 1. A block 51 included in the disturbance

compensator 10 multiplies the disturbance estimation signal τ_{dest} by $1/(gm_n \cdot Kt_n)$ to produce the disturbance compensation signal β that is required for causing the voice coil motor 6 to generate a driving force having a magnitude corresponding to the disturbance estimation signal τ_{dest} . A subtractor 52 subtracts the disturbance compensation signal β from the voice coil motor control signal c_1 to generate the voice coil motor driving signal u_1 .

Next, the operation of the first estimator 13 will be described. The disturbance estimation signal τ_{dest} output from the block 41 is expressed by Expression (4).

$$\tau_{dest} = \frac{G_2}{s} \cdot (Va - Va_{est}) \quad \dots (4)$$

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Moreover, the output γ from the subtractor 37 is expressed by Expression (5).

$$\gamma = \tau_{est} + \left(G_1 + \frac{G_2}{s} \right) \cdot (Va - Va_{est}) \quad \dots (5)$$

15

The voltage estimation signal Va_{est} is expressed by Expression (6).

$$Va_{est} = Ea_{est} + (Ra_n + La_n \cdot s) \cdot Ia_{est} \quad \dots (6)$$

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The induced voltage estimation signal Ea_{est} is expressed by Expression (7).

$$Ea_{est} = \frac{Lb_n \cdot Kv_n}{J_n \cdot s} \cdot \gamma \quad \dots (7)$$

Expression (6) can be transformed into Expression (8) based on Expression (5) and Expression (7).

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$$Va_{est} = \frac{Lb_n \cdot Kv_n}{J_n \cdot s} \left[\tau_{est} + \left(G_1 + \frac{G_2}{s} \right) \cdot (Va - Va_{est}) \right] + (Ra_n + La_n \cdot s) \cdot Ia_{est} \quad \dots (8)$$

For the sake of simplicity of illustration, it is assumed that the value of the transfer function gm of the first driver 11 is equal to that of the transfer function gm_n of the 10 block 31. Thus, the driving current Ia is equal to the driving current estimation signal Ia_{est} . Furthermore, assuming that Ra and La of the block 26 are equal to Ra_n and La_n of the block 36, respectively, the voltage drop $(Ra + La \cdot s) \cdot Ia$ that occurs as the driving current Ia is passed through the driving coil 6a is equal to the voltage drop $(Ra_n + La_n \cdot s) \cdot Ia_{est}$ that occurs as the driving current estimation signal Ia_{est} is passed therethrough. Thus, Expression (9) 15 holds.

$$(Ra + La \cdot s) \cdot Ia = (Ra_n + La_n \cdot s) \cdot Ia_{est} \quad \dots (9)$$

Moreover, assuming Expression (10) holds,

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$$\frac{Lb \cdot Kv}{J} = \frac{Lb_n \cdot Kv_n}{J_n} \quad \dots (10)$$

subtracting the left and right sides of Expression (8) from the left and right sides of Expression (3), respectively, while using Expressions (9) and (10), yields Expression (11).

$$Va - Va_{est} = \frac{Lb_n \cdot Kv_n}{J_n \cdot s} \left[\tau + \tau_d - \tau_{est} - \left(G_1 + \frac{G_2}{s} \right) \cdot (Va - Va_{est}) \right] \quad \dots (11)$$

The driving torque estimation signal τ_{est} represents an estimated value of the driving torque τ of the voice coil motor 6. Assuming that τ_{est} is equal to τ , Expression (11) can be rewritten as Expression (12).

10

$$Va - Va_{est} = \frac{Lb_n \cdot Kv_n}{J_n \cdot s} \left[\tau_d - \left(G_1 + \frac{G_2}{s} \right) \cdot (Va - Va_{est}) \right] \quad \dots (12)$$

15 By transforming Expression (12) using Expression (4), one can derive the relationship between the disturbance τ_d acting upon the head supporting mechanism 8 and the disturbance estimation signal τ_{dest} , obtaining Expression (13).

$$\tau_{dest} = \frac{\frac{Lb_n \cdot Kv_n}{J_n} G_2}{s^2 + \frac{Lb_n \cdot Kv_n}{J_n} G_1 \cdot s + \frac{Lb_n \cdot Kv_n}{J_n} G_2} \cdot \tau_d \quad \dots (13)$$

20 It can be seen from Expression (13) that the first estimator 13 is capable of estimating the actual disturbance τ_d with a secondary delay system from the voice coil motor driving signal u_1 and the voltage signal Va through the loop in the one-dot-chain-

line block of FIG. 2.

Where the natural angular frequency (estimated angular frequency) of the secondary delay system is denoted by ω_e and the damping factor is denoted by ζ , the constants G_1 and G_2 for stabilizing the operation of the first estimator 13 can be expressed as Expression (14) and Expression (15), respectively. Then, Expression (13) can be expressed as Expression (16).

$$G_1 = 2\zeta\omega_e \cdot \frac{J_n}{Lb_n \cdot Kv_n} \quad \dots (14)$$

$$G_2 = \omega_e^2 \cdot \frac{J_n}{Lb_n \cdot Kv_n} \quad \dots (15)$$

10

$$\tau_{dest} = \frac{\omega_e^2}{s^2 + 2\zeta\omega_e \cdot s + \omega_e^2} \cdot \tau_d \quad \dots (16)$$

As described above, in FIG. 2, the block 51 of the disturbance compensator 10 outputs to the subtractor 52 the disturbance compensation signal β generated by multiplying the disturbance estimation signal τ_{dest} by $1/(gm_n \cdot Kt_n)$. The subtractor 52 subtracts the disturbance compensation signal β from the voice coil motor control signal c_1 to generate the voice coil motor driving signal u_1 . The disturbance compensation signal β is a correction signal required for causing the voice coil motor 6 to generate a driving force having a magnitude corresponding to the disturbance estimation signal τ_{dest} . The disturbance compensation signal β is multiplied by $(gm \cdot Kt)$ through the first driver 11 and the voice coil motor 6. Thus, in the block 51, the disturbance estimation

signal τ_{dest} is multiplied by $1/(gm_n \cdot Kt_n)$ in advance such that the disturbance compensation signal β multiplied by $(gm \cdot Kt)$ is equal to the disturbance estimation signal τ_{dest} .

The voice coil motor driving signal u_1 is expressed by Expression (17).

$$u_1 = c_1 - \frac{1}{gm_n \cdot Kt_n} \cdot \tau_{dest} \quad \dots (17)$$

5

The output of the adder 27 is expressed by Expression (18).

$$gm \cdot Kt \cdot u_1 + \tau_d \quad \dots (18)$$

10

Assuming that gm is equal to gm_n and Kt is equal to Kt_n , Expression (18) can be rewritten as Expression (19) using Expressions (16) and (17).

$$gm \cdot Kt \cdot c_1 + \frac{s^2 + 2\zeta\omega_e \cdot s}{s^2 + 2\zeta\omega_e \cdot s + \omega_e^2} \cdot \tau_d \quad \dots (19)$$

15

Based on Expression (19), the block diagram of FIG. 2 can be illustrated in a simplified form using the transfer function G_d as shown in FIG. 3A.

Herein, it is assumed that the transfer function G_d is expressed as Expression (20).

20

$$Gd(s) = \frac{s^2 + 2\zeta\omega_e \cdot s}{s^2 + 2\zeta\omega_e \cdot s + \omega_e^2} \quad \dots (20)$$

FIG. 3B approximately represents the frequency characteristic of the transfer function $Gd(s)$ by a thick line. If the angular frequency is lower than ω_e , the gain 5 is smaller than 0 dB. In this frequency band, the gain is attenuated by an attenuation ratio of -20dB/dec (decade) as the angular frequency ω decreases. (Herein, "dec" means "tenfold".) That is, the transfer function $Gd(s)$ has a low cutoff filter characteristic which suppresses an angular frequency lower than the angular frequency ω_e .

As described above, in the magnetic disk apparatus according to the present 10 embodiment of the present invention, the disturbance τ_d which acts on the head supporting mechanism 8 is estimated by the first estimator 13 and is cancelled using the disturbance estimation signal τ_{dest} . Specifically, before the disturbance τ_d affects the positioning system, the disturbance τ_d is passed through the transfer function $Gd(s)$ which functions as if it is a low cutoff filter. Thus, the disturbance which acts on the head supporting 15 mechanism 8 is suppressed, and the reliable head positioning is achieved.

FIG. 4 is a block diagram showing another part of the structure of the positioning system in the magnetic disk apparatus of the present embodiment, illustrating the second driver 14, the second estimator 15, the adder 16, the position error detector 17, the first controller 18 and the second controller 19.

20 In FIG. 4, the second driver 14 represented by a block of the transfer function Ap multiplies the fine adjustment actuator control signal c_2 output from the second controller 19 by Ap to output the driving voltage V_p for the fine adjustment actuator 7.

The second estimator 15 represented by a block of the transfer function K_p

estimates a displacement of the magnetic head **2a** which occurs when the driving voltage V_p is input to the fine adjustment actuator **7**, so as to output the displacement estimation signal x_{2est} . In the present embodiment, the fine adjustment actuator **7** is formed by a thin film piezoelectric element having characteristics that cause a displacement generally proportional to the applied voltage. Thus, it is understood that the driving voltage V_p is generally proportional to a displacement of the magnetic head **2a** which occurs when the driving voltage V_p is applied to the fine adjustment actuator **7**. Therefore, the fine adjustment actuator control signal c_2 output from the second controller **19** is multiplied by K_p to generate the displacement estimation signal x_{2est} .

The adder **16** adds together the first head position estimation signal x_{1est} output from the first estimator **13** and the displacement estimation signal x_{2est} output from the second estimator **15** so as to output the second head position estimation signal x_{est} .

A one-dot-chain-line block on the upper left in FIG. 4 corresponds to the position error detector **17** of FIG. 1. The position error detector **17** is formed by a switch **61** and a subtractor **62**. The position signal x of the magnetic head **2a** is input to the switch **61** at a terminal **A**. The position signal x is detected by reading, with the magnetic head **2a**, the servo information recorded on the magnetic disk **1** in advance at a predetermined angular interval. On the other hand, the second head position estimation signal x_{est} output from the adder **16** is input to the switch **61** at a terminal **B**. The subtractor **62** subtracts the position signal x or the second head position estimation signal x_{est} from a target position signal r for the magnetic head **2a**, so as to generate the position error signal e .

A one-dot-chain-line block on the lower center in FIG. 4 corresponds to the first controller **18** of FIG. 1. The position error signal e and the displacement estimation signal x_{2est} are added together by an adder **72**, and a resultant addition signal is input to a

block 71. The block 71 subjects the addition signal to digital filter processing of the transfer function $G_1(z)$ to generate the voice coil motor control signal c_1 . The transfer function $G_1(z)$ is expressed by Expression (21).

$$G_1(z) = K_1 \left[1 + h_1(1 - z^{-1}) + L_1 \frac{z^{-1}}{1 - z^{-1}} \right] \quad \dots (21)$$

5

In this expression, z^{-1} denotes a one-sample delay, and K_1 denotes the proportional gain. The coefficients h_1 and L_1 are constants representing frequency characteristics, h_1 being a differential coefficient and L_1 being an integral coefficient.

10 The second controller 19 subjects the position error signal e to digital filter processing of the transfer function $G_2(z)$ as in the first controller 18, so as to output the fine adjustment actuator control signal c_2 . The transfer function $G_2(z)$ is expressed by Expression (22).

$$G_2(z) = K_2 \left[\frac{z^{-1}}{1 - z^{-1}} \right] \quad \dots (22)$$

15

In this expression, K_2 denotes the proportional gain.

FIG. 5A through FIG. 5C illustrate an exemplary operation of the switch 61 which is performed when the position error signal e is generated in the position error detector 17. FIG. 5A is a chart illustrating the timing at which the servo information recorded on the magnetic disk 1 is read by the magnetic head 2a at a predetermined

sampling cycle to generate the position signal x . A solid box ■ indicates the time when the position signal x is generated. FIG. 5B is a chart which illustrates the cycles when the switch 61 is connected to the terminal A or the terminal B. At the time when the servo information can be sampled, the magnetic head 2a can read the servo information to generate the position signal x . Therefore, at such a time, the switch 61 is connected to the terminal A so that the position error detector 17 generates the position error signal e using the position signal x . On the other hand, at the time when the servo information cannot be sampled, it is not possible to generate the position signal x . Therefore, the switch 61 is connected to the terminal B so that the position error detector 17 generates the position error signal e using the second head position estimation signal x_{est} . In the example illustrated in FIG. 5, the cycle of switching between the terminal A and the terminal B is a 1/2 of the sampling cycle of the servo information. That is, the position error signal e is generated at a cycle that is a 1/2 of the sampling cycle of the servo information.

As described above, the first head position estimation signal x_{1est} is obtained by integrating the velocity estimation signal v_{est} for the magnetic head 2a in the first estimator 13. The first head position estimation signal x_{1est} is an estimation result for the position of the magnetic head 2a which has been displaced due to the driving of the voice coil motor 6. Assuming that the position x_0 of the magnetic head 2a at a certain time t_0 has been precisely determined by detecting the servo information, the first head position estimation signal x_{1est} at time $t_0 + \Delta t$ is expressed using the velocity estimation signal v_{est} as Expression (23).

$$x_{1est}(t_0 + \Delta t) = x_0 + \int_{t_0}^{t_0 + \Delta t} v_{est} dt \quad \dots (23)$$

In this expression, Δt denotes the cycle of switching the switch **61** between the terminal **A** and the terminal **B**. Every time the first head position estimation signal $x_{1\text{est}}$ is generated, a correction is made to the first head position estimation signal $x_{1\text{est}}$ while referring to the correct and latest magnetic head position detected by sampling the servo information (i.e., position x_0). That is, the first head position estimation signal $x_{1\text{est}}$ is sequentially corrected using the servo information, such that the generated first head position estimation signal $x_{1\text{est}}$ is always correct.

The displacement estimation signal $x_{2\text{est}}$ for the fine adjustment actuator **7** is generated by multiplying the fine adjustment actuator control signal c_2 , which is a second control signal required for driving the fine adjustment actuator **7**, by the transfer function K_p in the second estimator **15**. This is achieved by utilizing the characteristic of the thin film piezoelectric element which is a constituent of the fine adjustment actuator **7** such that the piezoelectric element causes a displacement generally proportional to the voltage applied thereto.

Thus, the second head position estimation signal x_{est} , which is generated by adding together the first head position estimation signal $x_{1\text{est}}$ and the displacement estimation signal $x_{2\text{est}}$ by the adder **16**, is a correct estimation result for the position of the magnetic head **2a**. Even when the switch **61** is connected to the terminal **B**, it is possible to generate the correct position error signal e .

The voice coil motor control signal c_1 and the fine adjustment actuator control signal c_2 are generated from the position error signal e by the first controller **18** and the second controller **19**, respectively. In the example illustrated in FIG. 5A through FIG. 5C, the position error signal e is generated at a cycle that is a 1/2 of the sampling cycle of the servo information, and accordingly, the voice coil motor control signal c_1 and the fine adjustment actuator control signal c_2 are also generated at a cycle that is a 1/2 of

the sampling cycle of the servo information. FIG. 5C is a chart illustrating the timings when the voice coil motor control signal c_1 and the fine adjustment actuator control signal c_2 are generated. An open box \square indicates the time when the voice coil motor control signal c_1 and the fine adjustment actuator control signal c_2 are generated.

5 As shown in the timing chart of FIG. 5A through FIG. 5C, according to the present embodiment, at the time when the head position signal x cannot be detected by reading the servo information with the magnetic head 2a, the position error signal e is generated using the second head position estimation signal x_{est} which indicates the estimated position of the magnetic head 2a. That is, it is possible to generate the position
10 error signal e without directly using the servo information. Thus, the generation cycle of the position error signal e is shortened such that the control frequency of the positioning system is increased without increasing the number of servo sectors, i.e., without decreasing the data format efficiency. As a result, precise positioning of the magnetic head is achieved, and a highly reliable magnetic disk apparatus is provided.

15 The second head position estimation signal x_{est} is obtained by adding together the first head position estimation signal x_{1est} generated by the first estimator 13 and the displacement estimation signal x_{2est} generated by the second estimator 15. The first estimator 13 generates the first head position estimation signal x_{1est} based on the voice coil motor driving signal u_1 and the voltage signal V_a detected by the voltage detector 12. The
20 second estimator 15 generates the displacement estimation signal x_{2est} based on the fine adjustment actuator control signal c_2 . Basically, these signals can be generated independently of the sampling cycle of the servo information. Thus, as seen in the example of FIG. 5, the generation frequency of the position error signal e is not limited to a 1/2 of the sampling cycle of the servo information. The position error signal e may be
25 generated at a shorter cycle.

In the present embodiment, the multipliers, adders, subtractors and integrators included in the first estimator 13 and the disturbance compensator 10 are formed by analog filters, but the present invention is not limited thereto. It is a matter of course that the same effects are obtained even when these elements are formed by digital filters. The present embodiment has been described while exemplifying a magnetic disk apparatus, but the present invention is not limited thereto. It is a matter of course that the present invention is applicable to an optical disk apparatus, a magneto-optical disk, and the like.

In the above embodiment, the piezoelectric element that constitutes the fine adjustment actuator 7 causes a displacement generally proportional to the applied voltage, but the present invention is not limited thereto. The piezoelectric element that constitutes the fine adjustment actuator 7 may only have a certain relationship between the applied voltage and the displacement.

The fine adjustment actuator 7 is not limited to an actuator including a piezoelectric element. As a matter of course, any other type of actuator may be used as the fine adjustment actuator 7 (see, for example, "A MEMS Piggyback Actuator for Hard-Disk Drives", JOURNAL OF MICROELECTROMECHANICAL SYSTEMS, VOL. 11, NO. 6, pp 648-654, DECEMBER 2002, "An Electrostatic Micro Actuator for a Magnetic Head Tracking System of Hard Disk Drives.", TRANSDUCERS '97, 1997 International Conference on Solid-State Sensors and Actuators, Chicago, June 16-19, 1997, pp 1081-1084).